



S&H Form: (2/01)

REPL	Y/AMENDMENT
FEE	TRANSMITTAL

Attorney Docket No. 392.1627

Application Number 09/265,432

Filing Date March 10, 1999

First Named Inventor Akihiro TERADA et al.

Group Art Unit 3661

AMOUNT ENCLOSED		\$400.00	\$400.00 Examiner Name		T. NGUYEN			
	FEE	CALCUL	ATION (fees effective 10	0/01/00)	,		
CLAIMS AS AMENDED	Claims Remaining After Amendment	Highest N Previously		Number Extra	Rate		Calculations	
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INDEPENDENT CLAIMS	6	-	6 =	0	X \$ 84	= 00	0.00	
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Total of above Calculations =							400.00	
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(2) If entry (2) is less than 20, change entry (2) to "20".								
(2) If entry (2) is less than 20, change entry (2) to "20". (4) If entry (4) is less than entry (5), entry (6) is "0". (5) If entry (5) is less than 3, change entry (5) to "3".								
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Deposit Account No. 19-3935								
De	Deposit Account Name STAAS & HALSEY LLP							
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Typed Name	Patrick J. Stanzione			Reg. No.	40,434			
Signature Patrul 7		lan	lance		Date	10/	15/2001	
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RESPONSE UNDER 37 CFR 1.116 EXPEDITED PROCEDURE

EXAMINING GROUP 3661

Docket No.: 392,1627

IN THE UNITED STATES PATENT AND TRADEMARK OFFICE

In re the Application of:

Akihiro TERADA et al.

Serial No. 09/265,432

Confirmation No. Unassigned

Filed: March 10, 1999

Examiner: T. NGUYEN

Group Art Unit: 3661

ROBOT SYSTEM AND MACHINING METHOD WITH ROBOT SYSTEM

<u>AMENDMENT AFTER FINAL</u>

Assistant Commissioner for Patents Washington, D.C. 20231

Attention: BOX AF

Sir:

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GROUP 3600

This is in response to the Final Office Action mailed May 22, 2001, and having a period for response set to expire on August 22, 2001. A Petition for a two-month extension of time, together with the requisite fee for same, is submitted herewith, thereby extending the period for response to October 22, 2001.

Reconsideration of the claims is respectfully requested. The following remarks are respectfully submitted.

IN THE SPECIFICATION:

Please AMEND the third partial paragraph at page 11 as follows:

A tool unit 12 according to the third embodiment is constituted by an attaching portion 12a for attaching the tool unit 12 to the robot wrist 1a, an axis 12b in an L shape extended from the attaching portion 12a in parallel with an attaching face of the robot wrist 1a (perpendicular to the final axis 1 of the movable arm of the robot) and bent perpendicularly at a distal end thereof, an additional rotational axis 12c provided at a distal end of the axis 12b, a first additional variable

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